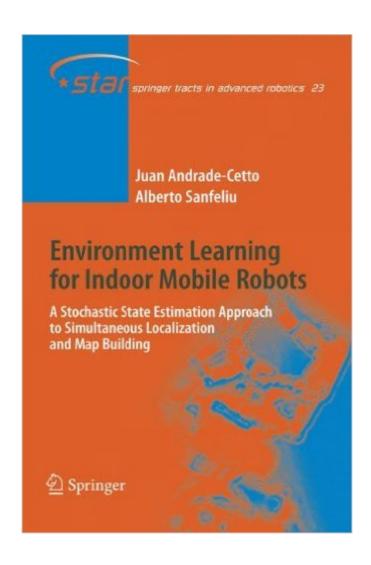
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# Environment Learning For Indoor Mobile Robots: A Stochastic State Estimation Approach To Simultaneous Localization And Map Building (Springer Tracts In Advanced Robotics)





# Synopsis

This monograph covers theoretical aspects of simultaneous localization and map building for mobile robots. These include estimation stability, nonlinear models for the propagation of uncertainties, temporal landmark compatibility, as well as issues pertaining the coupling of control and SLAM. One of the most relevant topics covered in this monograph is the theoretical formalism of partial observability in SLAM.

### **Book Information**

Series: Springer Tracts in Advanced Robotics (Book 23)

Paperback: 136 pages

Publisher: Springer; Softcover reprint of hardcover 1st ed. 2006 edition (November 30, 2010)

Language: English

ISBN-10: 3642069312

ISBN-13: 978-3642069314

Product Dimensions: 6 x 0.4 x 9 inches

Shipping Weight: 9.6 ounces (View shipping rates and policies)

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